

1 Docket: POC2003.01

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4 **PANORAMIC VIDEO SYSTEM WITH REAL-TIME**
5 **DISTORTION-FREE IMAGING**

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7 **ORIGIN OF THE INVENTION**

8

9 The invention described herein was made in the performance of work
10 under a USMC contract No. M67854-03-C-1006, and is subject to the provisions
11 of public law 96-517 (35 USC 202) in which the contractor has elected to retain
12 title.

13

14 **FIELD OF THE INVENTION**

15

16 The present invention relates generally to the field of special video camera
17 systems and more specifically to a real-time 360° panoramic video system which
18 utilizes a panoramic annular mirror, video camera and unique unwrapping
19 software which provides a seamless, distortion-free horizontal view of the
20 panoramic image.

21

22 **CROSS-REFERENCE TO RELATED APPLICATIONS**

23

24 The present invention takes priority from provisional application Serial No.
25 60/485,336 filed on July 3, 2003.

26

BACKGROUND OF THE INVENTION

Panoramic optical systems which can be employed to provide a 360° field of view, are known. By way of example, U.S. Patent No. 6,459,451 discloses a catadioptric lens which provides a 360° field of view. Such optical systems can be used advantageously with a camera to provide a system capable of imaging an entire 360° field such as an entire room or landscape from a unitary location using a single camera without requiring scanning or stitching multiple images. However, such lenses provide an image which is not readily interpretable by observers unless the image is first "unwrapped". The image of a 360° field of view lens is annular or doughnut-shaped and is therefore distorted and not readily discernible by a human observer. It is therefore necessary to convert that image or "unwrap" it into a relatively two-dimensional format such as a horizontal view on a relatively flat medium such as physically on film or electronically on a computer screen. The unwrapping process consists of a mathematical transformation such as by conversion of each picture element or pixel and is preferably accomplished in a manner which results in little or no distortion which would otherwise reduce the quality of the resulting flat image. Such pixel-by-pixel transformations are typically very complex and require complicated and time consuming computer programs, especially for reasonable levels of resolution and images having large numbers of pixels. Consequently, it has not been possible heretofore to exploit panoramic lens technology to provide a real-time unwrapped video image with acceptable resolution.

A system which could provide real-time unwrapped video images derived from a panoramic lens and video camera would be highly advantageous for a variety of useful applications. By way of example, such a system could provide security surveillance over a continuous all-around field of view using a unitary display with just one observer. Such a system could also be mounted on a transport mechanism and used for military or police reconnaissance purposes or for robotic imaging. It could also be used for medical visualization and for traffic

1 awareness systems. It can be tailored to be compatible with internet
2 transmission, wireless systems and can be designed for video image
3 compression to reduce transmission bandwidth requirements. Once it becomes
4 convenient to "unwrap" a panoramic video image in real time with little or no
5 distortion and with an acceptable level of resolution, a host of useful and
6 advantageous applications become feasible and readily available.

SUMMARY OF THE INVENTION

The present invention in its preferred embodiment combines a panoramic annular lens system (PAL), a unitary video camera and a PC-based software system that unwraps a 360° video image into a seamless, distortion free horizontal image in real time. The PAL system comprises two mirrors, namely, a hyperboloidal mirror and an ellipsoidal mirror interconnected by a 360° circular refracting front or entrance aperture lens and having a rear or exit aperture adjacent a collector lens. The PAL system of the preferred embodiment has a 360° horizontal field of view and a 90° vertical field of view in a 40mm diameter compact package. The invention is not limited to any particular type of lens system. In fact, there are numerous lens systems for providing a 360° panoramic view. The video camera may be a CCD or CMOS based device having a pixel resolution of either 1280 x 1024 (high resolution) or 720 x 480 (NTSC). The unwrapping system is a radiometric ray tracing program carried out using a computer's graphics card capabilities to produce highly efficient regional transformation while minimizing software overhead. The result is real time, high resolution 30 fps conversion from a spherical distorted image to a flat panoramic image in Cartesian coordinates. A graphic user interface (GUI) permits selection of any breaking point (any center line of the panoramic image) as well as zoom in and zoom out capability and built-in calibration.

1 **BRIEF DESCRIPTION OF THE DRAWINGS**

2

3 The various embodiments, features and advances of the present invention
4 will be understood more completely hereinafter as a result of a detailed
5 description thereof in which reference will be made to the following drawings:

6

7

8 FIG. 1 is a schematic diagram of a panoramic annular lens structure which
9 may be employed in the present invention;

10

11 FIG. 2, comprising FIGs. 2a and 2b, shows photographic top and side
12 views, respectively of the lens structure of FIG. 1;

13

14 FIG. 3 is a photographic view of the lens structure of FIG. 1 shown
15 integrated with a CCD camera;

16

17 FIG. 4, comprising FIGs. 4a and 4b, is a photographic illustration of a PAL
18 image before and after clipping, respectively;

19

20 FIG. 5 is a photographic representation of the unwrapped version of the
21 PAL image of FIGs. 4a and 4b;

22

23 FIG. 6, comprising FIGs. 6a, 6b, 6c and 6d, provides photographic views
24 of the image of FIGs. 4a and 4b in wrapped form in two different camera
25 resolutions and in unwrapped form in the same two resolutions, respectively;

26

27 FIG. 7 is a schematic diagram of an alternative embodiment of a
28 catadioptric omnidirectional ultra-wide-angle camera;

29

30 FIG. 8 is a simplified illustration of panoramic stereo imaging using a
31 double parabolic mirror;

1 FIG. 9 is a schematic diagram showing the design of a multilevel parabolic
2 mirror and camera;

3

4 FIG. 10 is a schematic diagram of panoramic imaging using a convex
5 reflecting mirror;

6

7 FIG. 11 is a schematic diagram of panoramic camera system useful for
8 day and night operation;

9

10 FIG. 12 is a schematic diagram of an annular flat mirror used in the
11 system of FIG. 11;

12

13 FIG. 13 is a schematic diagram of panoramic imager having a second
14 medium wavelength infrared optical channel;

15

16 FIG. 14 is a schematic diagram of the hemispheric view circular
17 projection of a circular fisheye lens;

18

19 FIG. 15 is a geometric diagram of a spherical coordinate mapping of the
20 circular fisheye lens;

21

22 FIG. 16, comprising FIGs. 16a and 16b, is a geometrical representation of
23 spherical and angular mapping, respectively;

24

25 FIG. 17, comprising FIGs. 17a and 17b, is a photographic view of the
26 original and converted images, respectively, of a circular fisheye lens;

27

28 FIG. 18 is a computer screen representation of the graphic user interface
29 for real-time conversion (“unwrapping”) software of the preferred embodiment of
30 the invention;

31

1 FIG. 19 is a computer screen representation of an image captured by a
2 fisheye video camera system in full frame at 30 fps;
3

4 FIG. 20 is a 1500x1000 Cartesian computer screen image converted at 30
5 fps from the fisheye image of FIG. 19 using the “unwrapping” software of the
6 present invention;

7

8 FIG. 21 is a computer screen representation similar to that of FIG. 19 but
9 showing the effect of various calibration methods for reducing distortion;

10

11 FIG. 22 is a graphical representation of radiometric ray tracing from an
12 input plane to an output plane for a pixel block;

13

14 FIG. 23, comprising FIGs 23a, 23b and 23c, is a graphical representation
15 showing transformation process from an annular image to an undistorted
16 rectangular image;

17

18 FIG. 24 is a block diagram of software flow of real-time unwrapping used
19 in the present invention;

20

21 FIGs. 25 and 26 are schematic diagrams used to explain the use of
22 panoramic imagers as rangefinders; and

23

24 FIGs. 27 and 28 are schematic diagrams used to explain the addition of
25 zoom function to a panoramic imager.

1 **DETAILED DESCRIPTION OF PREFERRED EMBODIMENTS**

2

3

4 Panoramic Annular Lens (PAL)

5

6 The PAL lens is based on both reflection and refraction of light and offers
7 panoramic 360° field of view in an ultra compact packaging of only 40 mm
8 diameter. The PAL lens provides a vertical field of view such as -40° to +50°. As
9 shown in FIG. 1, the panoramic lens is a piece of glass that consists of a 360°
10 circular aperture (R1), a rear aperture (R2) connecting to a collector lens, a top
11 mirror (H) and a circular mirror (E). The viewpoint of the "virtual camera" is at the
12 plane (O) of the ellipsoidal mirror (E). With this geometry, the PAL sensor can
13 view the entire 360° scene around its vertical axis BC. The vertical field of view
14 is determined by the effective sizes and the locations of the circular mirror E and
15 the top mirror H. Usually the viewing angle is 90° vertically.

16

17 The PAL is shown in FIGs. 2a and 2b. To maintain wide camera angle
18 options, the PAL mounting is terminated with a C-type mount that fits most 1/3 in.
19 and 1/2 in. pick-up devices, including CMOS and CCDs. Selection of a pick-up
20 device is important because it defines the final image quality. The most
21 important characteristic is resolution, which should be on the order of 1000 pixels
22 per video line. Progressive mode pick-up devices are preferred because they
23 eliminate temporal video field disparity. A wide range of such devices is
24 available on the market, with the prices dropping as more market share goes to
25 HDTV camcorders such as the JVC GR-HD1, which can record video in 720p HD
26 format (1024x720 pixels in progressive scans at 30 fps). The PAL integrated
27 with a camera is shown in FIG. 3.

1 The image produced by the PAL lens is circularly symmetric, as seen in
2 FIG. 4a. The PAL lens maps all the space within a 360° azimuth and 90°
3 elevation into an annular ring image. The image can still be recognized, and it
4 has relatively low geometric distortion compared to other panoramic visualization
5 systems such as hyperbolic mirror-based 360° systems. The major advantage of
6 the PAL is that it keeps vertical lines straight, significantly reducing the
7 computational complexity of image unwrapping. Only part of the image in FIG.
8 4a can usefully be unwrapped, as seen in FIG. 4b. The center and outer edges
9 of 4a do not carry any useful visual information, and are discarded. We maintain
10 maximum resolution covering the entire annular ring image by optimizing the
11 relay lens between the PAL and the camera. The unwrapped image unfolded to
12 panoramic Cartesian coordinates is shown in FIG. 5.

13

14 The PAL assembly was extensively tested on several cameras with a
15 variety of pixel resolutions. We started with a standard NTSC camera, which
16 thus had 420×240 pixels per field. Next we tested the lens with progressive scan
17 cameras, one at 480×480 pixels and one at 1024×1024. For each PAL-camera
18 combination we unwrapped the image and normalized it to the reference camera
19 resolution by bicubic scaling. FIG. 6 compares the images. FIG. 6a shows the
20 image captured by the 1024×1024 pixel camera. FIG. 6b shows a 480×480 pixel
21 image. The corresponding unwrapped images are shown in FIG. 6c for
22 1024×1024 pixels and in FIG. 6d for 480×480. A detail of both images (a picture
23 on the wall) is magnified in both cases. As expected, close examination of the
24 detail from both images shows smoother edges and better color rendering for the
25 high-resolution image.

26

27 Catadioptric Ultra-Wide-Angle Camera with Parabolic Mirror

28

29 In an alternative panoramic vision approach, a catadioptric system creates
30 omnidirectional vision by means of a parabolic mirror. The catadioptric
31 omnidirectional ultra-wide-angle camera (CUWAC) consists of a miniature digital

1 videocamera mounted in a frame and aimed directly at the apex of a parabolic
2 mirror enclosed within a transparent hemisphere, as illustrated in FIG. 7. The
3 dioptic camera lens in FIG. 7 images the focus of the parabola onto a CCD
4 imager. This camera views in all directions within a hemisphere via a parabolic
5 mirror. A CCD camera with a dioptic imaging lens faces the mirror a few inches
6 away and produces a circular image of the reflection. This resulting circular
7 image can then be converted into a normal view in any direction. However, the
8 image quality varies a great deal across the field-of-view; the system
9 magnification is greater at the center of the image and gradually decreases as
10 the image height Y increases. This causes severe image degradation at the
11 field-of-view margins. To overcome this drawback, we extended the panoramic
12 imaging concept to two concentric parabolic mirrors that differ in curvature. In
13 the two-mirror system illustrated in FIG. 8, the axes of the mirrors are collinear,
14 and coincide with the optical axis of the dioptic camera. Each of the mirrors has
15 a profile radially symmetric around this axis. The major parabolic mirror causes
16 less demagnification, and captures those parts of the hemisphere at larger
17 angles with better resolution. The minor mirror has a higher curvature and
18 higher magnification, and captures the central parts of the scene, i.e., close to
19 the optical axis.

20

21 The CUWAC parabolic optics ensure that it has a single effective center of
22 projection, a single point through which all rays from a scene must pass on their
23 way to the camera lens. That design mimics a camera that takes in only linear
24 perspective, and allows the CUWAC computer software to generate linear
25 perspective images that are free of distortion.

26

27 Two cameras with fisheye lenses or parabolic mirrors mounted back-to-
28 back can produce views of 360°, a complete sphere, for surveillance or security
29 operations. In teleconferences, such a panoramic camera can show
30 simultaneously every participant seated around a table, in either hemispheric or
31 linear perspective. It will allow a mobile robot to view hemispheric scenes.

1 Placed atop a concert stage or above midfield during a sports event, the ultra-
2 wide-angle camera could provide a 360° view — an entire sphere — to viewers.
3 With a joystick or mouse, the viewers could bring any view to their screens, and
4 see not only hemispheric perspective but normal, undistorted, linear perspective.

5

6 The basic design of this multilevel parabolic mirror is shown in FIG. 9.
7 The projection center C of the hyperbolic mirror coincides with focal point F. The
8 perspective camera is modeled by an internal camera calibration matrix K, which
9 relates 3D coordinates $X = [x,y,z]^T$ to retinal coordinates $q = [q_u,q_v,1]^T$

10

$$11 \quad q = \frac{1}{z} KX \quad . \quad (1)$$

12

13 Analysis of Panoramic Imaging System

14

15 Research in remotely operated and autonomous systems has shown the
16 usefulness of imaging that can span a very wide field-of-view. If instead of a
17 small conic view, a camera can capture almost an entire hemisphere of visual
18 information (“view-sphere”) at a time, the imaging system gains several
19 advantages. First, it is not necessary to move the camera to fixate on an object
20 of interest, or to perform exploratory camera movements. Second, processing
21 global images of an environment or target scene is less likely to be affected by
22 regions of the image that contain poor information. Third, a wide field-of-view
23 eases the search for reference objects, as they do not disappear from the field-
24 of-view; it helps stabilize image processing algorithms tracking such features.
25 Fourth, a wide field-of-view makes it easier to distinguish image artifacts due to
26 rotation of the camera from image artifacts due to object translation. The ability
27 to view and image an environment panoramically is useful in applications ranging
28 over machine vision, surveillance, collision avoidance, computation of ego-
29 motion, simple and easy detection of objects moving in the environment, and
30 robotics.

1
2 Reflective optics is cost effective and robust for global imaging. A camera
3 placed below a convex reflecting surface can observe large fields-of-view (see
4 FIG. 10). The mirror profile can be designed for angular gain to extend the
5 camera viewing geometry. With an appropriately shaped mirror, cameras that
6 typically have visual fields-of-view of $\sim 30^\circ$ can now image a full 360° in azimuth
7 θ , and up to $\pm 120^\circ$ in elevation Φ . FIG. 10 illustrates how a ray reflecting off the
8 reflector surface is directed into the camera viewing cone. Such an imaging
9 device has obvious advantages: first, being a passive sensor it has minimal
10 power requirements. Second, it has the potential to be extremely robust, since
11 the sensor is purely solid state and has no moving parts. Third, curved mirrors
12 can be made relatively free of the optical distortion that is typical of lenses.
13

14 Cameras with convex mirrors can acquire imagery instantly at video rates;
15 they can be compact, and can cost relatively little to produce. Commercial
16 "fisheye" lenses tend to be much more costly and bulkier than mirrors. In
17 addition, camera optics based on convex mirrors can have well defined
18 mathematical relationships that can be coded into the image processing and data
19 filtering to map the curved geometry of the view-sphere onto the 2D planar pixel
20 array. There are no simple and cost effective purely optical means for correcting
21 the image deformation that occurs in going from a 3D representation to a 2D
22 representation. A fundamental difficulty with panoramic imaging using a curved
23 reflective surface is that image resolution depends on position within the image.
24 In images from standard spherical convex reflectors, resolution depends upon
25 elevation. Visual patches at high elevations are quite different in resolution from
26 those near the horizontal, because they capture smaller solid angles of visual
27 space than do equatorial patches. Designing the mirror profiles to be
28 equiangular, transforms a curved image into a cylindrical projection, preserving a
29 linear relationship between the angle of incidence of light onto the mirror surface
30 and the angle of reflection into the camera with respect to the center of the
31 detector array. This ensures that the camera maintains uniform resolution of the

1 environment in the vertical plane independent of elevation angle, which is very
2 important to high quality panoramic imaging. Left unaccounted for in both mirror
3 design and image processing, vertical nonuniformity causes poor resolution
4 across a given target scene.

5

6 POC Panoramic Imager for Day/Night Operation

7

8 FIG. 11 illustrates a modular visible/infrared camera system. Light from
9 the scene is incident on a hyperbolic mirror. The surface profile of this mirror
10 (i.e., conic constant, radius of curvature, and aperture size) is designed in such a
11 way that the focus of the hyperbolic curve acts as the camera projection center,
12 where all rays appear to intersect. Alignment of the mirror with the cameras in
13 this system is critical to maintain the linear relationship between the elevation
14 and camera viewing angles. Those rays satisfying the single viewpoint
15 relationship are reflected by the hyperbolic mirror surface, and are incident on an
16 annular flat mirror (see FIG. 12) that is oriented at 45° with respect to the nadir.
17 Half of the light hitting the annular mirror passes through the clear aperture
18 (lower elevations of the viewing geometry) within the central portion of the mirror,
19 and half the light (higher elevations of the viewing geometry) is reflected at 90°.

20

21 The light propagating along each optical path is collected by a zoom lens.
22 The video zoom lens for this optical system is a commercial off-the-shelf product
23 with a focal length varying from 8 mm to 48 mm, a working distance that ranges
24 from 1.2 m to ∞ , and compatibility with 1/2 in. format detectors, and has F
25 numbers that range from F1.2-16 and angular fields-of-view from 44.6° to 8°.
26 The two zoom lenses enable us to independently adjust each arm of the sensor.
27 They need not be set to the same zoom magnification (i.e., the blur spot size can
28 be set to fill up the pixel array); this can improve the resolution in each portion of
29 the visual image, which has the benefit of enabling the system to equalize
30 resolution as a function of viewing elevation for the panoramic imager. The
31 minimum blur spot size for the panoramic imager with this zoom lens is estimated

1 to be ~1.5 to 2 times the diffraction limit. The light from each zoom lens is
2 imaged onto a commercially available 3 megapixel, 1/2 in. format, CMOS silicon
3 detector chip. The number of pixels in each detector array is 2048x1520, with a
4 7 μm linear pitch. The larger pixel size improves the low light sensitivity of the
5 camera chip to ~0.05 lux with reduced fixed pattern noise. According to the
6 manufacturer's specifications, the SNR for this camera is 78 dB. The camera
7 operates in noninterlaced mode (progressive scan), and produces full frame
8 readouts at video rates of 30 frames per second. Full asynchronous image
9 capture with programmable partial scan (region-of-interest mode of operation)
10 gives these cameras the flexibility for numerous daytime/nighttime applications.
11 Both color and monochrome versions of the camera are available. In the color
12 version the overall resolution is reduced by the Bayer color filter; the resolution is
13 about 1/3 for each of the primary colors.

14

15 Because silicon is sensitive into the near infrared region (700 nm to 1100
16 nm) of the spectrum, the imager can be used for nighttime surveillance.
17 Moreover, the panoramic imager is designed to be modular so that a second
18 channel can easily be introduced to extend the nighttime vision capability into the
19 mid-wave infrared (3 to 10 μm) region. This design is envisioned with a flat
20 mirror, coated for >98% reflectivity over the MWIR spectrum. The 45° orientation
21 of the flat mirror directs the light toward a second optical channel (see FIG. 13).

22

23 The rest of the optical layout would be similar to that described previously,
24 with the addition of PtSi or HgCdTe detectors and infrared zoom lens assemblies
25 to detect the infrared scene. Note that these infrared focal plane arrays are only
26 QVGA scale (320x240 pixels), with a linear pitch of 12 μm , so overall resolution
27 would be reduced. However, a multicolor panoramic imager could track targets
28 under conditions that would be beyond the capabilities of the silicon-based
29 detectors. At night infrared irradiance is about two orders of magnitude greater
30 than that in the visible spectrum under moonlight conditions. Additionally one

1 may apply sophisticated image interpolation techniques to increase the image
2 resolution.

3

4 Mathematical Foundation for Panoramic Image Unwrapping

5

6 The circular fisheye lens projects a hemispheric view of the surroundings
7 into a circular image as shown in FIG. 14. The panoramic image is a 180°
8 fisheye projection. The projected panoramic image covers a full 180°
9 horizontally, but because of cropping of the frame it covers substantially less
10 vertically, ~ 135°.

11

12 In constructing the unwrapping process, the unit assigned to the limiting
13 circle of the 180° fisheye projection is radius, and its center is chosen as the
14 image origin. Points in the image are assigned polar coordinates (r, θ) and
15 converted to spherical coordinates with angular coordinates θ and ϕ , where θ is
16 longitude and ϕ is the angle from the axis of projection as in Eq. (2). FIG. 15
17 geometrically illustrates the spherical mapping of a circular fisheye image. The
18 transformation from polar to spherical coordinates keeps θ the same and
19 transforms r into ϕ . FIG. 16 shows the angles of mapping coordinates (FIG. 16a)
20 and a geometrical representation of angular coordinate conversion (FIG. 16b).

21

$$22 \begin{pmatrix} x_b \\ y_b \\ z_b \end{pmatrix} = \begin{pmatrix} \cos \alpha & 0 \\ \sin \alpha \sin \beta & \cos \beta \\ -\sin \alpha \cos \beta & \sin \beta \end{pmatrix} \begin{pmatrix} x_d \\ y_d \end{pmatrix} + \begin{pmatrix} \sin \beta \\ -\sin \alpha \cos \beta \\ \cos \alpha \cos \beta \end{pmatrix} \quad (2)$$

23

24 Then we can map the hemicube to the fisheye image, and from this we
25 can convert a 180° fisheye image (see FIG. 17a) into a normal perspective
26 image, with the result shown in FIG. 17b. The mapping equations used for
27 transformations of coordinates are:

28

1

$$\begin{pmatrix} \phi_b \\ \varphi_b \end{pmatrix} = \begin{pmatrix} \arctan\left(\frac{y}{x}\right) \\ \arctan\left(\frac{\sqrt{x_b^2 + y_b^2}}{z}\right) \end{pmatrix} \quad (3)$$

2

3

$$\begin{pmatrix} x_v \\ y_v \end{pmatrix} = \begin{pmatrix} r_v \cos \theta \\ r_v \sin \theta \end{pmatrix} \quad (4)$$

4

5

$$\begin{pmatrix} \theta_v \\ r_v \end{pmatrix} = \begin{pmatrix} \phi_b \\ r \varphi_b \end{pmatrix} \quad (5)$$

6

7 The mapping pipelines the following steps for continuous operation of
8 incoming images:

9

- 10 1. Image plane to angular coordinate
11 2. Angular coordinate to spherical coordinate
12 3. Find inverse transformation

13

14 $(x_d, y_d) \xrightarrow{(\alpha, \beta)} (x_b, y_b, z_b) \xrightarrow{r} (\phi_b, \varphi_b) \xrightarrow{r} (\theta_v, r_v) \xrightarrow{r} (x_v, y_v) \quad (6)$

15

16 Some of the necessary equations involve spherical coordinates. The
17 angles θ and ϕ in the following equations are related to a canonical Cartesian
18 (x, y, z) coordinate frame by:

19

20 $x = r \cdot \sin(\delta) \cdot \cos(\theta) \quad (7)$

21 $y = r \cdot \sin(\delta) \cdot \sin(\theta) \quad (8)$

22 $z = r \cdot \cos(\delta) \quad , \quad (9)$

23 and their inverse:

24 $r^2 = x^2 + y^2 + z^2 \quad (10)$

$$\cos(\theta) = x / \sqrt{x^2 + y^2} \quad (11)$$

$$\sin(\theta) = y / \sqrt{x^2 + y^2} \quad (12)$$

$$\cos(\phi) = z/r \quad (13)$$

$$\sin(\phi) = \sqrt{x^2 + y^2} / r . \quad (14)$$

Real-time Panoramic Video Conversion Software

This section discusses the fundamentals of video mapping software architecture and design issues. The conversion system is coded and debugged on Microsoft Windows Video technology and additional video manipulating architecture. The performance and stability of the software have been optimized for real-time video conversion software.

Designs and Functionalities of Video Mapping Software

The preferred embodiment of the invention comprises real-time panoramic video conversion software to convert video from circular polar coordinates to Cartesian panoramic video with 2000×1000 video resolution at 30 frames per second.

The real-time panoramic conversion software has been developed in Microsoft Direct3D and DirectShow. Microsoft Direct3D has full capabilities for rendering and mapping images in real time. Direct3D can directly access and manipulate video memory without calling upon operating system services, so the graphics can be manipulated in hardware. The following lists summarize the capabilities of Direct3D.

- 1 Direct3D functionality
- 2 • Device-dependent access to 3D video-display hardware in
3 a device-independent manner
- 4 • Support for 3D z-buffers
- 5 • Switchable depth buffering
- 6 • Transformation and clipping
- 7 • Access to image-stretching hardware
- 8 • Exclusive hardware access
- 9 • Immediate access to the transformation, lighting, and
10 rasterization 3D graphics pipeline
- 11 • Software emulation if hardware acceleration is not available
- 12

13 Direct3D low level functionality

- 14 • 3D coordinate systems and geometry
- 15 • Shading techniques
- 16 • Matrices and transformations
- 17 • Vectors and vertices
- 18 • Copying surfaces
- 19 • Page flipping and back buffering
- 20 • Rectangles
- 21

22 Direct3D application level functionality

- 23 • Bump mapping
- 24 • Environment mapping
- 25 • Geometry blending
- 26 • Indexed vertex blending
- 27 • Patches
- 28 • Point sprites
- 29 • Procedural pixel shader
- 30 • Procedural vertex shaders
- 31 • Quaternions

- Spotlights
- Tweening
- Vertex blending
- Volume textures.

Microsoft introduced new technology to apply Direct3D to video applications gluelessly for real-time manipulation of video with mapping, blending, textures, and shadings. The following highlights DirectShow technology.

- Architecture for streaming media
- High-quality playback of multimedia streams
- File based
- Network stream
- Universal decoding capability
- Glueless interface with other DirectX technology
- Automatic detection of hardware acceleration support
- Common Object Model (COM)-based interface.

The real-time video software was developed around the core functions of Microsoft Direct3D and DirectShow, but the innovative and unique architectural and hierarchical development of this software is the first in the multimedia world that can convert and display panoramic video in real time without noticeable latency.

Customizing Microsoft Video Mixing Renderer

The Video Mixing Renderer (VMR) is a new DirectShow filter, available only for Windows XP Home Edition and XP Professional, replacing both Overlay Mixer and Video Renderer, and adding many new mixing features. In terms of

1 both performance and breadth of features, the VMR represents the new
2 generation in video rendering on the Windows platform.

3

4 VMR supports the following new features:

5

- 6 • Real mixing of multiple video streams, taking advantage
7 of the alpha-blending capabilities of Direct3D hardware
8 devices.
- 9 • The ability to plug in your own compositing component
10 to implement effects and transitions between video
11 streams entering the VMR.
- 12 • True windowless rendering. It is no longer necessary
13 to make the video playback window a child of the
14 application window to play video back. The VMR's new
15 windowless rendering mode makes it easy for applications
16 to host video playback within any window without having
17 to forward window messages to the renderer for renderer-
18 specific processing.
- 19 • A new renderless playback mode, in which applications
20 can supply their own allocator component to get access to
21 the decoded video image prior to its being displayed on
22 the screen.
- 23 • Improved support for PCs equipped with multiple monitors.
- 24 • Support for Microsoft's new DirectX Video Acceleration
25 architecture.
- 26 • Support for high-quality video playback concurrently in
27 multiple windows.
- 28 • Support for DirectDraw Exclusive Mode.
- 29 • 100% backward compatibility with existing applications.
- 30 • Support for frame stepping and a reliable way to capture
31 the current image being displayed.

- 1 • The capability for applications to easily alpha-blend their
2 own static image data (such as channel logos or UI
3 components) with the video in a smooth flicker-free way.
4

5 The VMR depends entirely on the graphics processing capabilities of the
6 computer display card; the VMR does not blend or render any video on the host
7 processor, as doing so would greatly impact the frame rate and quality of the
8 video being displayed. The new features offered by the VMR, particularly
9 blending of multiple video streams and/or application images, depend strongly on
10 the capabilities of the graphics card. Graphics cards that perform well with the
11 VMR have the following hardware support built in:

- 12
- 13 • Support for YUV and "non-power of 2" Direct3D texture surfaces.
14 • The capability to StretchBlt from YUV to RGB DirectDraw surfaces.
15 • At least 16 MB of video memory if multiple video streams are to
16 be blended. The actual amount of memory required depends on
17 the image size of the video streams and resolution of the display
18 mode.
19 • Support for an RGB overlay or the capability to blend to a YUV
20 overlay surface.
21 • Hardware accelerated video decoding (support for DirectX
22 Acceleration).
23 • High pixel fill rates.

24

25 In our conversion software, we specifically customized VMR renderless
26 mode to maximize the capability and flexibility of the software to better
27 manipulate the controlling parameters. VMR renderless mode features a
28 customized allocator for the customized rendering surface, and a customized
29 renderer for the customized rendering mode.

1
2 In renderless playback mode, the application
3
4 • Manages the playback window.
5 • Allocates the DirectDraw object and the final frame buffer.
6 • Notifies the rest of the playback system of the DirectDraw object
7 being used.
8 • "Presents" the frame buffer at the correct time.
9 • Handles all resolution modes, monitor changes, and "surface
10 losses" – advising the rest of the playback system of these events.

11
12 The VMR

13
14 • Handles all timing related to presenting the video frame.
15 • Supplies quality control information to the application and the
16 rest of the playback system.
17 • Presents a consistent interface to the upstream components of
18 the playback system, which are not aware that the application is
19 performing the frame buffer allocation and the rendering.
20 • Performs any video stream mixing that may be required prior to
21 rendering.

22
23 Basically, the conversion software calls various functions of VMR and
24 customized DirectX surfaces to make them fit our specific purpose, which is real-
25 time non-linear image transformation with streaming video in progress. We
26 purposely coded this software with VMR-7 for Windows XP only. DirectX 9 with
27 VMR-9 code migration can be made software compatible with other operating
28 systems such as Windows 9x and Windows 2K as well as Windows XP.

1 Real-time Panoramic Unwrapping Software

2
3 The real-time conversion software implements Direct3D Immediate Mode
4 with geometrical relationships to convert spherical images to Cartesian images in
5 arbitrary perspective. The world management of Immediate Mode is based on
6 vertices, polygons, and commands that control them. It allows immediate access
7 to the transformation, lighting, and rasterization 3D graphics pipeline. Image
8 conversion is applied to primitives so that there is no intervening overhead from
9 other interfaces and direct access hardware functions. We tested our software
10 with Nvidia GeForce, ATI Radeon, and Intel low-profile VGA chips. The final
11 code is compatible with most video acceleration chips and processors, so it can
12 be used with major hardware platforms. FIG. 18 shows the graphic user
13 interface (GUI) for the conversion software. FIG. 19 shows fisheye video in the
14 GUI. FIG. 20 shows the corresponding panoramic video converted from the
15 spherical fisheye image in real time (on the fly) at the full 30 frames/second. The
16 unwrapping algorithm may be optimized to alleviate distortion near frame edges.
17 FIG. 21 shows enhanced functions of the player.

18

19 The following list summarizes the player capabilities and functions:

20

- 21 • Universal playback capability (MPEG, AVI, and more)
- 22 • Bitmap capture (right-button click)
- 23 • Calibration by clicking three points on a circle (shows circle in red)
- 24 • Adjustments of aspect ratio for non-square pixel digitizers
- 25 • Change center of view in 360° panoramic viewing mode
- 26 • Zoom, pan, and tilt
- 27 - F1 and F2 for zoom-in and -out
- 28 - Arrow buttons for pan and tilt
- 29 • Status bar indicates movie size, capture device, playing time,
- 30 resolution of movie and display, performance, and viewing angles
- 31 • Capture (and DV) device properties.

1
2 And performance parameters are:
3

- 4 • Panoramic and 360° view: ~30 frames/second with anti-aliasing
5 and anisotropic filters
6 • 180° view: ~20 frames/second and up depends on processor
7 and video card with anti-aliasing and anisotropic filters
8 • Video resolution – full screen up to 2048x1536 pixels.
9

10 Radiometric Ray-Tracing (R^2T)
11

12 R^2T yields a single-valued mapping of radiometric quantities such as
13 luminance (brightness) from an input plane to an output plane as shown in FIG.
14 22 for any continuous optical medium.
15

16 This procedure is illustrated in FIGs. 23a, 23b and 23c, progressing from
17 an annular image (a) to a distorted unwrapped image (b), and then to a corrected
18 unwrapped image (c). Transformation from a distorted (b) panoramic image of a
19 French window into a perfect (c) panoramic image is by R^2T , is based on a priori
20 ray-tracing, equivalent to transformation from a curved system of coordinates into
21 the Cartesian coordinate system. To perform this operation in real time, we
22 divide the 120° horizontal viewing area into a large number of pixel blocks, 10x10
23 or more, and develop a uniform transformation for each block separately.
24

25 Hardware Acceleration
26

27 Conventional omni-view systems use an image by image conversion
28 process to generate transformed (or unwrapped) video with or without hardware
29 acceleration. Yet, conventional transformations (of commercial off the shelf
30 software) are done pixel by pixel and require tremendous CPU power to
31 transform the spherical or cylindrical images to Cartesian or plain view images.

1 The Applicant's approach to this problem is to increase the performance many
2 fold (typically about ~30 times faster than any existing software in current
3 market), and yet retain the quality of images or video. Animation applications
4 require tremendous processing power for manipulating images because they
5 must provide the real time conversions of perspective, zoom level, morphing,
6 rendering, and so on. Many competing video card manufacturers have been
7 developing these 3D animation engines for Video card (or Graphics Processing
8 Unit) with very high performance graphical performance for better games. We
9 have found that using these high-performance features of GPUs or 3D engines
10 makes it possible to achieve real-time performance on omni-view systems for
11 real-time video conversions.

12

13 The inventive software utilizes vertex based transformation rather than
14 pixel by pixel processing. Each vertex includes coordinates, color, and image
15 plane information for perspectives. Number of vertices for a single image is
16 limited to 65536 because we did not find any quality enhancement for more
17 vertices than 65536. The following Graphics Processing Units' (GPU) internal
18 functions are used for hardware acceleration: Lighting, Geometry Blending,
19 Alpha, Anisotropic filter or linear filters for distortion correction, 3D textures, Cube
20 textures, Clamping, and Vertex and pixel Pipelining.

21

- 22 • Lighting: provides detailed brightness and optical calibration
- 23 • Geometry and Vertex Blending: increases the realism of transformed
24 image
- 25 • Alpha Blending: provides the character and drawing overlays to primary
26 video
- 27 • Anisotropic filter: increases the quality by minimizing transforming
28 distortion
- 29 • 3D textures: easier for 3D coordinate transformation
- 30 • Cube textures: for perfect transformation on arbitrary perspective
- 31 • Clamping: for out-of-bound image control

- 1 • Vertex and pixel Pipelining: increases image manipulation in many orders
2 of performance.

3

4 In summary, the actual image manipulation of colors, lines, points, and
5 perspective changes are all done in hardware or in GPU more specifically.
6 Furthermore, video presentation is also done in hardware with no intervention to
7 other functionalities such as 3D manipulation of vertices. The only CPU load is
8 to calculate the vertex coordinate changes according to the governing equations,
9 e.g. transforming spherical coordinates to Cartesian coordinates.

10

11 Software Flow

12

13 As shown in FIG. 24, the software comprises four modules: 1) video
14 capturing, 2) image conversion, 3) presenting image as image manipulation
15 module, and 4) rendering image on video surface. The software provides many
16 video capturing features such as DV capture, video capture with any Microsoft
17 ActiveMovie compliances (16 bit), video capture with WDM (windows driver
18 model – 32 bit) drivers for video streaming, and third party capture drivers that
19 are recognized by Windows operating system.

20

21 Video capture module often introduces significant overheads and
22 resources for software. However, providing proper pipelining and buffering
23 avoids those problems.

24

25 The image conversion module converts incoming bitmaps in pipelined
26 fashion with multithreading (or super pipelining), so that minimum delay is
27 guaranteed during the process. In this module, Microsoft Direct3D and DirectX
28 functions are utilized for image conversions and manipulation of video memory.
29 The image manipulation is done in primitive level rather than in application level,
30 so that we can have maximum level of programmability and flexibility. In

1 addition, the optimization of performance is possible but the coding is extremely
2 tedious because it requires programming in C++, C, and assembly languages.
3

4 The presentation module is responsible for preparing video, bitmap
5 capture, calibration (feed-back to image conversion module), and drawing
6 circles or showing performance information on top of video.
7

8 Finally, the rendering module is heavily dependent on hardware (video
9 engine) and mostly done by using built-in functions of Microsoft DirectShow. This
10 module sends the final image streams to video memory.
11

12 FIG. 24 illustrates the overall software architecture for our real-time omni-
13 view video software of the presently preferred embodiment.
14

15 Panoramic Rangefinder

16

17 Mirror-based panoramic omnidirectional imagers have a blind zone
18 surrounding the vertical axis (see FIG. 25). Consequently, two such imagers can
19 be positioned along the same vertical axis, one above the other, without any
20 mutual obscuration of the fields of view. This use of two such imagers produces
21 a stereo effect and provides an ability to retrieve the distance to an object based
22 upon parallax angle measurement (see FIG. 26).
23

24 Panoramic Imager With Zoom

25

26 Mirror-based panoramic imagers form an image in two steps. In the first
27 step the omnidirectional object space is transferred into an imaginary intermedial
28 ring image above the mirror (see image A' of FIG. 27). In the second step the
29 projection lens transfers the imaginary intermedial image to the real image at the
30 receiver plane (see image A" of FIG. 27). Zone 0'0 can be used for the direct
31 view of the upper field zone with zoom ability. An additional lens (negative zoom

1 lens of FIG. 28) creates an imaginary image of the upper conical object field at
2 the plane O'0, of FIG. 28. Then a projection lens fills zone 0"0", at the receiver
3 plane with the real image of the intermedial image.

4

5 Having thus disclosed preferred embodiments to illustrate the various
6 unique features of the invention, it will now be apparent that a panoramic video
7 system according to the present invention may be implemented in various ways,
8 some of which are not necessarily described herein. Therefore, the scope hereof
9 is not to be limited to the specific disclosed embodiments, but only by the
10 appended claims and their equivalents.

11

12 We claim:

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